Abstract

The invention concerns a method and a system for controlling a first robot and at least one other robot, the at least one other robot being calibrated relative to the first robot by the determination of at least one coordinate transformation of the first robot relative to at least one other robot and said at least one transformation is stored in a control device of the other robot, wherein also the first robot is calibrated relative to the other robot by the determination of at least one independent coordinate transformation and said at least one independent transformation is stored in a control device of the first robot.

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